

**IN THE CLAIMS:**

Please amend the claims as follows:

Claim 1 (Currently Amended): A gait pattern generating device of a walking robot for generating a gait pattern from a desired ZMP trajectory using ZMP preview information, wherein

a driving quantity of the center of gravity in one moment is determined on the basis of a fed-back motion state of the center of gravity in the moment and a previewed or planned future ZMP trajectory, so as to generate a walking motion in real time;

a table-cart model is used for simplifying a characteristic of the walking robot;  
and

the fed-back motion is determined based on a time-derivative of acceleration of a cart of the table-cart model in which the cart corresponds to the center of gravity.

Claim 2 (Original): The gait pattern generating device of a walking robot using ZMP preview information according to Claim 1, wherein

the walking robot is a bipedal walking robot.

Claim 3 (Original): The gait pattern generating device of a walking robot using ZMP preview information according to Claim 1 or 2, wherein

the previewed or planned future ZMP trajectory is corrected based on a detailed dynamical model of the robot in addition to a basic model using a table-cart model.

Claim 4 (Canceled).